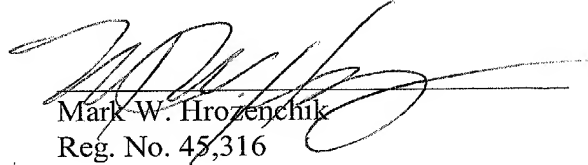


Prompt and favorable action is solicited.

Respectfully submitted,


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MARKED-UP VERSION

25. (Amended) A controller for controlling the acceleration of an armature of an electric drive, with means for generating a partly synthesized high quality acceleration error correction signal \underline{z} , comprising:

an accelerometer mechanically attached to the armature of the electric drive to measure a true armature acceleration α , made available as a measured armature acceleration value \underline{b}_m , equal to the product of the true armature acceleration α and an acceleration measurement transfer function $F_g(p)$, the acceleration measurement transfer function $F_g(p)$ having a complex frequency variable p whereby the function [and being defined by the relationship] $F_g(p)$ equals one when p equals 0;

means for measuring a substitute acceleration signal b_E , made available as a measured acceleration signal, \underline{b}_{Em} ;

means to scale the measured armature acceleration value \underline{b}_m and the measured acceleration signal \underline{b}_{Em} such that the relationship of $\underline{b}_m = \alpha \cdot F_g(p) = \underline{b}_{Em} \cdot F_g(p)$ is satisfied;

a first filter for filtering the measured armature acceleration signal \underline{b}_m with a first filter transfer function of $F_T(p)$, to obtain a first filter output signal $\underline{x} = \underline{b}_m \cdot F_T(p)$, in which the first filter transfer function $F_T(p)$ has the complex frequency variable p [and is further defined by the relationship $F_T(p)$ equals one when p equals 0];

a second filter for filtering the measured acceleration signal \underline{b}_{Em} with a second filter transfer function of $F_H(p)$, to obtain a second filter output signal $\underline{y} = \underline{b}_{Em} \cdot F_H(p)$; and

means for combining the first and second filter outputs to form the partly synthesized high quality acceleration error correction signal $\underline{z} = \underline{b}_m \cdot F_T(p) + \underline{b}_{Em} \cdot F_H(p)$.

40. (New) The controller according to claim 25, wherein the function $F_T(p)$ equals one when p equals 0.